IN THE SPECIFICATION:

Please replace the paragraph at page 7, lines 20-30 of the specification with the following replacement version thereof. Such change merely corrects a typographical error, no new matter is added.

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According to further embodiments, the basic spatial-modulation method described herein is enhanced. The baseline spatial-modulation imaging (SMI) staring sensor performs high-resolution point-target acquisition over a WFOV. It also provides a low-resolution conventional image of the scene over that WFOV. However, in some cases it is desired to provide an operator with a high-resolution view not only of point targets but also of all of the scene's spatial-frequency components. For example, six sensors, each covering a 90° FOV, could be distributed over an aircraft to detect point targets over a FOV that subtends a solid angle of 4π steradians. It could also be desired to provide an operator in that aircraft with the ability to see in any direction, at high-resolution, over such a field of view. This is sometimes referred to as a "glass cockpit."

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Please replace the paragraph at page 8, lines 26-29 of the specification with the following replacement version thereof. Such change merely corrects a typographical error, no new matter is added.

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The benefit of foveated SMI (or FEI) is that the total function of WFOV acquisition of an unresolved point target and NFOV recognition of the target can be performed with many fewer pixels (detector elements) than a conventional high-resolution sensor with no SMI.

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Please replace the paragraph at page 9, line 25-26 of the specification with the following replacement version thereof. Such change merely corrects a typographical error, no new matter is added.

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Fig. 6 is a flow diagram of a foveal enhancement procedure according to an illustrative embodiment of this invention; and

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Please replace the paragraph at page 14, lines 6-9 of the specification with the following replacement version thereof. Such change merely corrects a typographical error, no new matter is added.

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If (because of scene motion) the clutter intensity in any particular output detector is different in frames V1 and V3, causing clutter leakage in the simple difference DIF = V1-V3, then this clutter leakage is reduced or attenuated in the balanced demodulation difference DIF_B = V2 – (V1 +V3)/2.

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